

Amendments to the Claims:

The following listing of claims will replace all prior versions, and listings, of claims in the application:

1.-7. (Canceled)

8. (Currently Amended) An articulated manipulator comprising:

a base;

first to sixth links arranged in series on the base; and

a plurality of joints rotatably connecting the base and the first link, and the two adjacent links out of the first to sixth links,

wherein, the joints include first and second coaxial joints and first to fourth diagonal joints,

the first link is connected to ~~a~~the base by the first coaxial joint for rotation about a rotation axis coaxial with an axis of the first link,

the first link and the second link are connected to each other by the first diagonal joint for rotation about a rotation axis inclined at an angle of 45 degrees relative to the first axis of the first link,

the second link and the third link are connected to each other by the second diagonal joint for rotation about a rotation axis inclined at an angle of 45 degrees relative to the axis of the second link, the rotation axis being parallel to the rotation axes of the first and second links,

the third link and the fourth link are connected to each other by the third diagonal joint for rotation about a rotation axis inclined at an angle of 45 degrees relative to the axis of the third link, the rotation axis being perpendicular to the rotation axes of the second and third links,

the fourth link and the fifth link are connected to each other by the second coaxial joint for rotation about a rotation axis coaxial with the axis of the fourth link, and

the fifth link and the sixth link are connected to each other by the fourth diagonal joint for rotation about a rotation axis inclined at an angle of 45 degrees relative to the axis of the fifth link.

9. (Currently Amended) The articulated manipulator according to ~~claim 1~~ claim 8, wherein the second link consists of two sublinks connected for rotation about their axes.

10. (Previously Presented) The articulated manipulator according to claim 8, wherein the sixth link is provided with a twist unit for connecting a predetermined terminal device to the sixth link so as to be rotatable about a rotation axis aligned with the axis of the sixth link.